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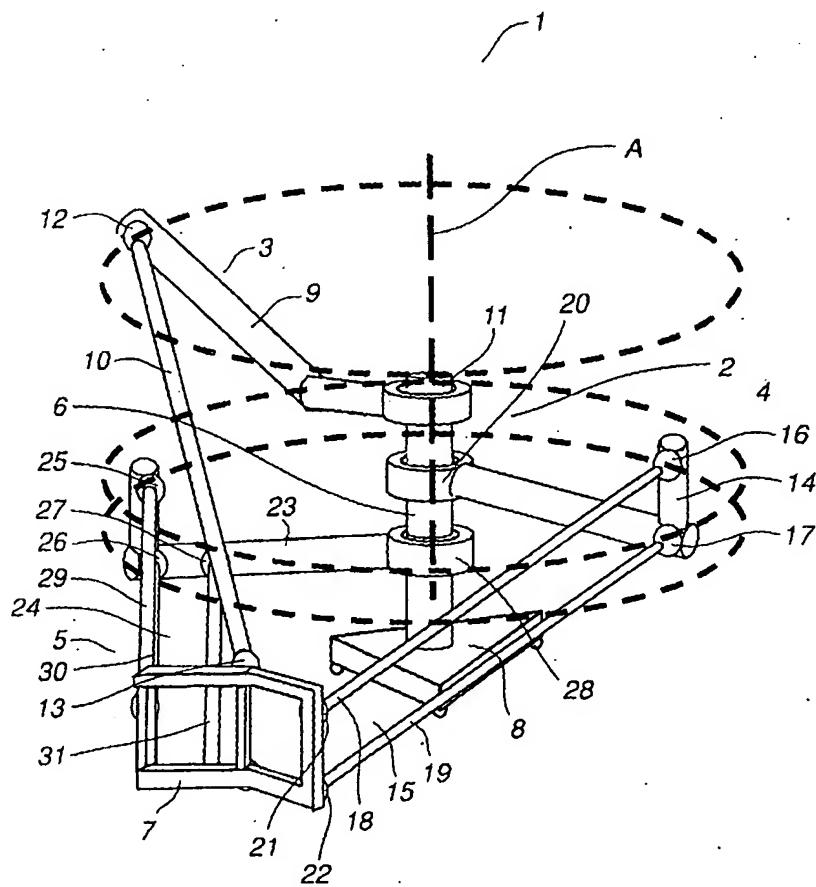
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- (71) Applicant (*for all designated States except US*): **ABB AB**
[SE/SE]; S-721 83 Västerås (SE).
- (72) Inventors; and
- (75) Inventors/Applicants (*for US only*): **KOCK, Sönke**
- (74) Agent: **ABB GROUP SERVICES CENTER AB**; Legal & Compliance/Intellectual Property, S-721 78 Västerås (SE).
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(54) Title: INDUSTRIAL ROBOT



(57) Abstract: An industrial robot including a parallel kinematic manipulator (2) of an object (7a) in space, where the manipulator (2) includes a stationary platform (6), a movable platform (7) for carrying the object (7a), at least three arms (3, 4, 5) connecting the platforms (6,7). Each arm comprises a first arm part () connected to the stationary platform for manipulating the movable platform (7).

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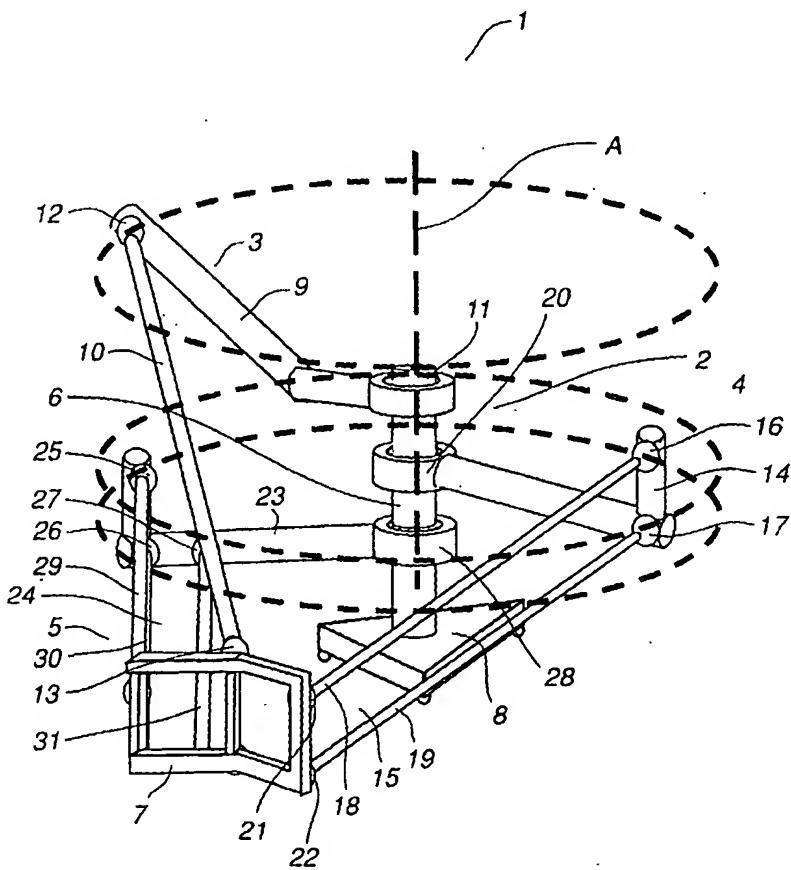
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OESTERLEIN, Roland [DE/DE]; Ernst-Rehm-Strasse
7, D-69124 Heidelberg (DE). BROGÅRDH, Torgny
[SE/SE]; Plåtverksgatan 140, S-724 79 Västerås (SE).
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[SE/SE]; S-721 83 Västerås (SE).
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5 Industrial Robot.

TECHNICAL FIELD

The present invention relates to an industrial robot, including a manipulator and a control unit
10 having means for automatically operating the manipulator. The manipulator comprises a parallel kinematic manipulator including at least three arms, each comprising a link arrangement. The three link arrangements together carry, directly or indirectly, a working platform member arranged to execute the function aimed at.

15 The determination "parallel kinematic manipulator", PKM, is defined as a manipulator comprising a first stationary element, a second movable element (platform) and at least three arms. Each arm comprises a supporting first arm part and a second arm part, the latter consisting of a link arrangement connected to the movable platform. Each first arm part is actuated by a driving means preferably arranged on the stationary element to reduce the moving mass. These
20 link arrangements transfer forces due to actuation of the supporting first arm parts when manipulating the movable platform.

BACKGROUND OF THE INVENTION

The well-known robot type named SCARA robot is a serial kinematic manipulator primarily used
25 for moving and rotating objects without changing the inclination of the objects. The manipulator comprises kinematic links coupled in series. These robots normally have four degrees of freedom in the x-, y-, z- directions and ϕ_z (rotation of the object about an axis parallel to the z-axis). For manipulating the object in the xy-plane, two arms coupled in series and working in the xy-plane are used. In order to achieve a movement in the z-direction a linear movement device is used.
30 This device is arranged either after the arms coupled in series or before the arms coupled in series. In the first case the arms coupled in series must move the drive assembly for the z-

movement and in the latter case the drive assembly for the z-movement must move the arms coupled in series. The drive assembly for the φ_z -movement will always be located at the extreme end of the kinematic chain of the robot.

- 5 Several of the properties concerning the SCARA-robot are improved with a robot, which manipulates an object through working in parallel, i.e. a parallel kinematic manipulator, PKM. According to the statements above, a serial kinematic robot comprises a large mass and thus becomes compliant with low mechanical natural frequencies, the accuracy is limited and large motor torques are required for accomplishing high acceleration, jerk and speed movements
10 possible.

A parallel kinematic robot is a design offering a high degree of load capacity, high stiffness, high natural frequencies and low weight. Three arms working in parallel are required to obtain manipulation of a platform in three degrees of freedom, i.e. the x, y and z-directions in a
15 Cartesian system of coordinates. Six arms working in parallel are required to obtain manipulation of a platform in all six degrees of freedom, i.e. the x, y, z directions and the rotation angle /inclination of an object arranged on the platform.

Ideally, an object ought to be manipulated by a total of six separate links, which transfer only
20 compressive and tensile forces to the manipulated object to obtain a stiff and accurate manipulation. Generally, the PKM comprises three up to six first arm parts. As an example, a manipulator with four arms designed for four degrees of freedom has second arm parts sharing the six separate links. This is only possible with certain combinations of the links, as for example, 2/2/1/1 or 3/1/1/1. 2/2/1/1 means that two supporting first arm parts are connected to the
25 respective second arm part, which comprises two links and another two supporting first arm parts are connected to the respective second arm part, which comprises a single link.

A known manipulator is manipulating a platform, which remains with unchanged inclination in the whole working area. The robot has three supporting first arm parts, each connected to a
30 second arm part, in kinematic parallelism. From this robot, it is known to arrange a total of six links optionally distributed on three first arm parts according to the combinations 2/2/2 or 3/2/1.

A known device for relative movement of a first element in relation to a second element according to the combination 2/2/2 is disclosed in the international application WO 99/58301. The three arms, each comprises a supporting first arm part connected to a second arm part, which includes a link arrangement. The first element is described as stationary and the second element
5 is manipulated in the x-, y- and z-direction by driving means. Each link arrangement is connected to a supporting first arm part and to the second element, respectively, by means of joints of 2 or 3 degrees of freedom. Each driving means comprises a stationary portion and a rotating portion, where the stationary portion is included in the first, stationary element. Using the reference numbers in the document, each driving means has its rotating portion connected to the first arm
10 parts 6, 7 and 8. The driving means 3 is pivoting the first arm part 6 and the driving means 4 is pivoting the first arm part 7 about the same geometrical axis 37. The third driving means 5 is pivoting the first arm part 8 about a geometrical axis 38, which is non-parallel to the pivoting axis 37. The third driving means 5 implies that upon pivoting of the supporting arm part 7 by means of the driving means 4 also the supporting arm part 8 will accompany as a consequence of the
15 fact that an axis 53 and also a gear wheel 10 will accompany the pivoting movement. Thus, the driving means 4 and 5 must accelerate more and are more heavily loaded compared with the driving means 3. Consequently, this manipulator design necessitates three different driving means designs with three different drive dimensions. This makes the design more complicated and the manipulator relatively expensive to process. Another consequence is that the first driving
20 means carries the highest moment of inertia and there will be an uneven distribution of the moment of inertia in the manipulator. Moreover, the mechanical natural frequencies will be lower because of the extra mass that axis 2 has to rotate, which gives a less accurate control at higher motion frequencies.

25 A device for relative movement of a first and a second element according to the second combination 3/2/1 is disclosed in the international application WO 97/33726. The device comprises a manipulator including three arms each arranged to connect a stationary and a movable platform. Each arm comprises a supporting first arm part and a second arm part connected to each other, where respective second arm part comprises a link arrangement. Three
30 actuators are fixed to the stationary platform and actuate one first arm part each. A first supporting arm part is connected to a second arm part linkage arrangement comprising three links

in parallel. Another first arm part is connected to a double link arrangement and still another first arm part is connected to a single link, where all links are connected to the movable platform.

The document US 5,539,291 shows a parallel kinematic manipulator. A stand sustains a biaxial 5 controllable supporting arm part. This arm part supports, in its turn, a second arm part, which sustains a movable object. A first and a third supporting arm pivoting around a common pivot axle are connected to the movable object via outer arms comprising belts with the function of a combination between an arm part and a four linkage. The outer arms and the second supporting arm are arranged to transmit compressive and tensile forces as well as torsion moments. The 10 result is a relatively bulky design of a manipulator with a limited operating volume. Moreover, the shown manipulator comprises less stiffness, lower accuracy and much lower mechanical natural frequencies when compared with a manipulator comprising arm parts transmitting only compressive and tensile forces.

15 A robot is operating within a volume needed for the application, which is referred to as the operating volume in the following. Furthermore, the volume outside the operating volume, which a manipulator needs for its own purpose, is referred to as the unused operating volume. Prior art includes a manipulator, which has a voluminous and expensive design with a limited operating volume (Figure 16 in the prior art). For certain robot applications, it is important due to 20 enormously high initial costs to make a PKM with a small unused operating volume in relation to the operating volume and which can work close to each other.

According to the conditions mentioned above, there is a need for an industrial robot with high accuracy and stiffness. Further, there is a need for a robot with an improved course of dynamic 25 forces and simultaneously an increased working volume in relation to the unused manipulator volume. Further, there is a need for a robot, which has the characters of rapidness and an exact movement. Additionally, there is a need for a robot design which makes the robots work close to each other.

30 The known industrial robots comprising a parallel kinematic manipulator do not satisfy this need.

SUMMARY OF THE INVENTION

The object of the invention is to provide a rapid PKM, defined above, that offers high accuracy, stiffness and an increased operating/unused operating volume ratio. A second object of the invention is to provide a method for a fast and accurate manipulation of an object. A third object
5 of the invention is to use a robot according to the first aspect and a method according to the second aspect for high accuracy operations.

These objects are achieved according to the invention in a first aspect by an industrial robot comprising the characteristic features of the independent claim 1, in a second aspect by a method
10 in an industrial robot for manipulating an object with high accuracy comprising the characteristic features of the independent claim 11, and a use of the method according to claim 15 and 16.

Preferred embodiments are described in the dependent claims.

The solution according to the first aspect of the invention is to provide an industrial robot
15 including a parallel kinematic manipulator for movement of an object in space. The manipulator includes a stationary platform, a movable platform for carrying the object and at least three arms connecting the platforms. Each of the at least three arms comprises a first arm part connected to the stationary platform for endless rotation around an axis.

20 The possibility for a first arm part to rotate more than 360° is referred to as endless rotation.

The parallel kinematic manipulator comprises at least three independent supporting first arm parts, each connected to a second arm part. The second arm parts together comprise in total 6 links with only axial forces and are arranged, as described above, to connect the platforms,
25 optimizing the overall accuracy and stiffness of the manipulator.

The at least three first arm parts of the parallel kinematic manipulator according to the invention are arranged with the possibility of endless rotation about one or several axes. Thus, the endless rotation of the PKM reduces the unused operating volume to one or several different cylindrical
30 volumes around respective axis of rotation and the unused operating volume is decreased. Another consequence of this design is that the minimum and maximum radial operating distance

between the movable platform and respective axis of rotation is increased and consequently, the operating volume is increased. A reduced unused operating volume and an increased operating volume results according to the invention in an increased operating/unused operating volume ratio.

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The robot according to the invention has a desirable dynamic character due to even dynamic force distribution and to lack of undesirable torsion and bending forces in the design. This results in high speed, acceleration and accuracy of the robot.

- 10 In one embodiment of the invention, the supporting first arm parts are arranged to rotate around one of at least two parallel axes. Each first arm part is arranged connected to the stationary platform and is actuated by a separate actuating means. Furthermore, actuating means is arranged to actuate only one single supporting arm part each and not actuating any part of the stationary platform or any other actuator. Therefore, the design of the robot according to the invention has a
15 decreased moving mass compared to prior art robots. It is possible to have low effect as well as low mass of the actuators actuating the arms. This minimizes the moment of inertia and maximizes the acceleration and speed capability of the robot at an available torque level. This design is free from sources of undesirable play. The result according to the invention is a robot design with low mechanical natural frequencies and transmission errors and therefore possessing
20 a minimum moment of inertia and even distribution of the same and furthermore a design free from undesirable stresses. This results in a robot, in accordance with the invention, having high accuracy and desirable dynamic performance.

- According to the invention, the robot comprises a manipulator with arms rotating around parallel axes, which reduce the unused operating volume, defined above. This results in a compact robot,
25 which due to the design has the premises of operating within a large operating volume. Furthermore, the robot according to the invention comprises a manipulator, which lacks positions with an arm extending undesirably in space during operation.

- 30 In one embodiment of the invention, a robot comprises three arms including one first arm part each. Each first arm part is arranged to rotate around an axis, which is parallel to and at a distance

from a rotation axis of one of the other first arm parts. Thus, the arms are arranged on a stationary platform to rotate around three different rotation axes.

According to the invention, a robot comprises three, four, five or six arms including one first arm part each. The three, four, five or six first arm parts are arranged to rotate around a common axis. Thus, the arms are connected to the stationary platform and arranged to rotate around a common rotation axis.

According to the invention, the robot comprises a universal column concept, which is suitable to arrange on a floor, on a wall, between two walls or from a ceiling irrespective of the orientation of the column. According to the invention, the stationary platform comprises a column arranged with a detachable robot stand in either end of the column.

According to the invention, the robot comprises three, four, five or six arms and is designed for manipulation in three, four, five or six degrees of freedom. There are also embodiments where a redundant arm is necessary to eliminate singularities in a working area of a robot. A singularity for a parallel robot is defined as a configuration where the manipulated platform gains one degree of freedom, which makes the platform impossible to control. Usually, the parallel arm structure will collapse when it enters a singularity. Moreover, the PKM will be very compliant and inaccurate close to a singularity.

According to the invention, at least one redundant arm is arranged to rotate an object to be manipulated. Two arms rotating the object offer a higher force of rotation compared to prior art robots comprising a local driving means arranged for rotation of the object.

According to still another embodiment of the invention, the robot comprises six arms connecting the movable platform with a second arm part comprising one link each. This robot design results in a robot, which manipulates one degree of freedom with each arm. It is named a 6 DOF manipulation parallel robot design, which obtains both the 3-degree of freedom positioning and the 3-degree of freedom orientation of a manipulated platform.

The solution according to the second aspect of the invention is to provide a method in an industrial including a parallel kinematic manipulator for movement of an object in space. The manipulator includes a stationary platform, a movable platform for carrying the object, at least three arms connecting the platforms and actuating means for actuating the arms.

5 The actuating means are individually actuating the arms to endless rotation in different planes.

According to the invention, the PKM comprises three, four, five or six arms arranged to rotate around a common axis in parallel planes. In one embodiment of the invention, six robot arms are brought to manipulate an object in one degree of freedom each. In still another embodiment, the
10 object is manipulated in constant inclination.

According to the invention, the PKM comprises three, four, five or six arms arranged to rotate around one of at least two separate parallel axes in parallel planes. Accordingly, the operation volume is brought to vary during rotation

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According to the invention, one alternatively two redundant arms are, defined above, bringing an object to be manipulated into endless rotation.

20 The solution according to the third aspect of the invention is to use a robot according to the first aspect and a method according to the second aspect for high accuracy operations, in for example applications measurements, laser cutting, assembly, disassembly, fettling of castings or machining.

25 In a further embodiment according to the fist aspect of the invention, a robot comprises three supporting first arm parts and two of them are secured relative to each other. This embodiment comprises a robot working in a plane (2DOF).

BRIEF DESCRIPTION OF THE DRAWING

30 The invention will be explained more closely by the description of different embodiments thereof and with reference to the appended drawing in which:

Figure 1 is an industrial robot according to the invention of the combination 3/2/1,

- Figure 2 is an industrial robot according to figure 1 arranged in a floor position,
Figure 3 is an industrial robot according to figure 1 arranged in a roof position,
Figure 4 is an industrial robot according to figure 1 arranged in a portable position,
Figure 5 is an industrial robot according to the invention of the combination 3/2/1
5 arranged with a redundant first arm part,
Figure 6 is an industrial robot according to the invention of the combination 2/2/1/1
comprising an extended movable platform,
Figure 7 is an industrial robot according to figure 6 arranged with a redundant arm,
Figure 8 is an industrial robot according to figure 7 with an extra kinematic degree of
10 freedom,
Figure 9 is an alternative embodiment of the robot according to the invention for
manipulation and rotation of a tool,
Figure 10 is a robot according to figure 5 comprising an alternative platform,
Figure 11 is a modification of the industrial robot of figures 1-4,
15 Figure 12 is an industrial robot according to the invention with six arms,
Figure 13 is an industrial robot according to figures 1-4,
Figure 14 is an industrial robot according to the invention with three arms rotating around
parallel axes,
Figure 15 shows three ceiling-mounted robots working side by side close to each other,
20 Figure 16 is figure 1 from the prior art document WO 97/33726
Figure 17 is an industrial robot according to the invention working in a plane.

DESCRIPTION OF THE PREFERRED EMBODIMENTS

Figure 1 is an industrial robot 1 comprising a manipulator 2 with three arms 3, 4, 5 arranged
25 rotating around a common axis A. The arms 3, 4, 5 are connecting a stationary column 6a and a
movable platform 7 in the combination 3/2/1 for carrying an object 7a (Figure 2) to be
manipulated. The column 6a is supported by a detachable stand 8, which is fixed to the ground.

The first arm 3 comprises a supporting first arm part 9 and a second arm part comprising a link
30 arrangement 10 pivotally connected in series via a joint 12. The supporting first arm part 9 is

rotationally attached to the column 6 through connecting means 11. The link arrangement 10 is pivotally connected to the movable platform 7 via a joint 13.

The second arm 4 comprises a supporting first arm part 14 and a second arm part comprising a
5 link arrangement 15 pivotally connected in series via joints 16 and 17. The supporting first arm part 14 is rotationally attached to the column 6a through connecting means 20. The link arrangement 15 comprises two links 18, 19 of the same length, arranged in parallel and pivotally connected to the movable platform 7 via joints 21 and 22.

10 The third arm 5 comprises a supporting first arm part 23 and a second arm part comprising a link arrangement 24 pivotally connected in serial via joints 25, 26 and 27. The supporting first arm part 23 is rotary attached to the column 6 through connecting means 28. The link arrangement 24 comprises three links 29, 30 and 31 of the same length, arranged in parallel and pivotally connected to the movable platform 7 via joints 32, 33 and 34 (not shown), respectively. The
15 supporting first arm parts 9, 14 and 23 are rotating about a common axis A and therefore their movements will be in parallel planes when actuated and this rotation is shown in figure 1 by the broken lines.

In one embodiment (not shown), the robot is used for manipulating the platform 7 in the xy-plane
20 with a constant position in the z-direction. This is made by keeping joint 12 vertically above joints 25 and 26 and mounting joint 13 vertically above joints 33 and 34. This is also achieved in an alternative embodiment by keeping joint 12 vertically above joints 16 and 17 and mounting joint 13 vertically above joints 21 and 22. The first arm part 9 is then either synchronously controlled with respect to the first arm part 23 and the first arm part 14, respectively.

25 Joint 12 is then kept vertically above joints 25 and 26 or alternatively above joints 16 and 17 by mechanical locking of the first arm part 9 (supporting joint 12) to the first arm part 23 (supporting joints 21 and 22), alternatively to the first arm part 14 (supporting joints 16 and 17). Another possibility is to control the first arm part 9 synchronously with the first arm part 23
30 respective the first arm part 14.

A possible change of position is made according to the following. The robot stand 8 (Figure 2) is dismounted from the first end 35 of the column 6, turned upside down and attached to the second end 36 of the column 6. Figure 3 is the industrial robot according to figure 2 after the change to a roof position. It is emphasized that the column 6 and the arms 3,4 and 5 have the same orientation
5 in both figures 1, 2 and 3.

Figure 4 is an alternative embodiment of the invention. The robot in figure 2 is detached from the roof position and equipped with a robot foot 37 attached to the first end 35 of the column 6. It is emphasized that the column 6 and the arm system have the same orientation in both figures 3 and
10 4.

The industrial robots in the Figures 1-4 are the same robot of the combination 3/2/1 comprising three arms 3, 4 and 5, which are designed for manipulating an object in the x-, y- and z-direction by means of force applying arrangements (not shown). The robot is designed to allow the
15 supporting first arm parts 9, 14 and 23 rotation about one single axis A, which they have in common. The second arm parts closest to the movable platform are the link arrangements 10, 15 and 24, respectively, and they share the necessary six links in the combination 3/2/1. The joints 12, 16, 17, 25, 26 and 27 are designed to allow a relative movement of three degrees of freedom between respective supporting arm parts 9, 14 and 23 and link arrangements 10, 15 and 24. Two
20 of the said three degrees of freedom consist of pivoting in all directions about two real or imaginary axes placed at an angle to each other and the third is in the form of rotation of an individual link about its longitudinal axis. In reality, the individual joints 12, 16, 17, 26 and 27 comprise ball joints or universal joints.

25 The link arrangement 10 is connected to the movable platform 7 through the joint arrangement 13. The link arrangement 15 is connected to the movable platform 7 through the joint arrangements 21 and 22. The link arrangement 24 is connected to the movable platform 7 through the joint arrangements 32, 33 and 34. The joints 13, 21, 22, 32, 33 and 34 are designed to allow a relative movement of two or three degrees of freedom between the link arrangement 10, 15, 24
30 and the movable platform 7, respectively. In reality, the individual joints 13, 21, 22, 32, 33 and

34 comprise universal joints or ball joints. In the former case, one degree of freedom in the form of rotation of an individual link about its longitudinal axis is eliminated.

The arms 4 and 5 are mainly manipulating the platform 7 in the x y-plane and the arm 3 is
5 manipulating the platform 7 mainly in the z-direction. The three arms together manipulate the position of the movable platform 7 under a constant inclination of the platform 7.

Figure 5 is an industrial robot of the combination 2/2/1/1 designed for manipulation of an object in four degrees of freedom, the x-, y-, z-direction and tilting. It comprises a robot according to
10 figure 1 reduced with the link 29 and completed with a fourth arm 38 arranged to rotate about the common axis A between the arms 3 and 4, connecting the stationary column 6 and the movable platform 7 via a first arm part 38a connected to a second arm part link arrangement 38b. When the first arm part 38a is rotated relative to the other arms, the platform 7 will be tilted, making it possible to adapt the platform orientation to the need of the application for the robot.

15 Figure 6 is an industrial robot according to the invention of the combination 2/2/1/1 with four arms 39, 40, 45 and 46. Each arm comprises a supporting first arm part 39a, 40a, 45a, 46a arranged to rotate about the axis A of the stationary column, and a second arm link arrangement 39b, 40b, 45b and 46b jointly connecting the respective first arm part and the movable platform.
20 The first arm parts manipulate the platform 7 via the second arm parts comprising links in the combination 2/2/1/1. The arm system is in this case designed for the manipulation of an object in four degrees of freedom, the x-, y-, z-direction and φ_z -rotation.

In Figure 6, the first arm part 39 and the second arm part 40 are arranged to manipulate the platform 7 mainly in the xy-plane. Each first arm part 39, 40 is connected to the extended movable platform 7 via one second arm part each comprising two parallel links and corresponding joints 41, 42 and 43, 44, respectively, and the links are arranged to rotate about a common axis B.

30 The third and fourth supporting arm parts 45 and 46 are arranged to manipulate the platform 7 mainly in the z-direction and to give the platform a φ_z -rotation. Thus, the arrangement will

manipulate the position of an object 47, its height and distance to the axis A, and also the rotation of the object about an axis B. The rotation is limited to $^{+}50^{\circ}$ about the axis B. This arm structure will not work with a 180° rotation.

- 5 The design described above with the two pairs of parallel links connected to the movable platform leads to parallelism between the axes A and B. However, there are positions where the autonomous height and direction are lost, called singularities. This means that there are positions where the manipulator loses control of the platform, positions where the platform actually will gain a degree of freedom.

10

- Further, Figure 6 is a robot comprising a platform 7, which is designed to comprise two parallel crank parts 7a and 7b connected by a third connecting part 7c. The joints 41, 42, 43 and 44 are arranged on the platform part 7a to rotate about a common z-axis B. The joints 41, 42, 43 and 44 are designed to allow a relative movement of two or three degrees of freedom. The second arm parts 45b and 46b are connected to the platform part 7b via joints 47 and 48, respectively. These joints are designed to allow a relative movement of two or three degrees of freedom and are arranged on the platform part 7b to rotate about a common axis C. The design of the robot in figure 6 allows an accurate rotation of the platform 7 of up to about $^{+}50^{\circ}$ around the axis B as mentioned above.

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- Figure 7 is a modification of figure 6 with a redundant arm 49 added, which comprises a first arm part 49a arranged to rotate about the A-axis between the supporting first arm parts 40a and 45a. The uppermost rotating first arm part 46a is mainly manipulating the height of the movable platform 7. The two lowest supporting first arm parts 39a and 40a, respectively, allow manipulation mainly in the xy-plane. The first arm part 45a, together with the redundant first arm part 49a, allows full rotation of the platform 7, defined as any number of turns, about the axis B. In singularity positions according to the robot in figure 6, the redundant arm 49 according to figure 7 is used to control the movement of the platform 7b. As an alternative, a servo for the redundant arm controls the force on the second arm link arrangement instead of its position to make the redundant control outside the singularity positions.

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An alternative to the arrangement in figure 7 is to connect part 7a of the platform to the redundant arm 49, whereby the position of part 7a is controlled. The first arm parts 45a and 46a are then used only for the rotation of the platform 7a. However, in this case the manipulation of the platform part 7a must be made independent of the position of the platform part 7a and therefore
5 an arrangement for the parallel movement of platform parts 7a and 7b is needed. This arrangement will add a kinematic degree of freedom through a single axis joint 50, which is shown in Figure 8. In this embodiment, the redundant second arm part 49b is connected to the platform part 7a, which is pivoting about the axis B. The platform part 7c comprises a double parallel four-link system allowing the platform part 7b to rotate about the axis C, which due to
10 the link system remains provided parallel to the axis A and B.

Figure 9 is an alternative embodiment of the robot according to the invention. The robot is of the second arm part combination 3/2/1 comprising links corresponding to the first arm parts 3, 4 and 5 in Figure 1. Two redundant arms 51 and 52, respectively, are arranged to bring a tool 53 arranged on the platform 7 in endless rotation. The tool 53 is arranged to rotate about the axis B,
15 which in its turn is parallel to both axes A and C.

Figure 10 is an alternative embodiment of the robot in Figures 1-4 comprising a redundant arm 56. The platform 7 is designed to comprise three parallel crank parts 7d, 7e and 7f, respectively,
20 connected by two connecting parts 7g and 7h. These five parts together form a pedal structure with a horizontally extended central part 7e carrying a tool 54 and two pedal parts 7g and 7h arranged in each end of the extended part 7e and connected to the arms 55 and 56 for rotation of the platform 7. The pedal parts 7d and 7f, respectively, are displaced 90° in relation to the axis of rotation. Rotation of the platform 7 results in tilting of the tool 54.
25

Figures 6, 7, 8, 9 and 10 are robots provided with two arms for rotation of an object to be manipulated.

Figure 11 is a robot according to the invention of the combination 2/1/1/1/1. The design of the
30 robot is a modification of the robot according to Figures 1-4, where the arm 4 is replaced by two arms 57 and 58, respectively, both comprising a first arm part 57a and 58a, respectively, and a

second arm part 57b and 58b, respectively. The second arm parts 57b and 58b, respectively, includes one single link each. The robot manipulates the platform 7 in five degrees of freedom.

Figure 12 is an industrial robot according to the invention of the combination 1/1/1/1/1/1, which
5 comprises six arms 59, 60, 61, 62, 63 and 64, respectively, each arm comprising a first arm part and a second arm part, the latter of which includes a single link. This robot has the possibility to manipulate all six degrees of freedom as defined above.

Figure 13 is a robot according to the invention of the combination 2/2/1 comprising a
10 manipulator with five degrees of freedom.

Figure 14 is an alternative industrial robot according to the invention comprising three arms 65, 66 and 67. Each arm comprises a supporting first arm part 65a, 66a and 67a, respectively, and these first arm parts are arranged to rotate around the parallel axes G, F and H, respectively. In
15 this embodiment the stationary column has a modified design adapted for the rotation of the arms. This embodiment allows endless rotation and results both in a operating volume and an unused operating volume, defined above, which varies over a revolution in both size and shape.

Figure 17 is an alternative industrial robot according to the invention comprising three arms 68, 69 and 70. Each arm comprises a supporting first arm part 68a, 69a and 70a, respectively, and two of these first arm parts, 68a and 69a are secured relative to each other through securing means 71. This robot is working in a plane (2DOF).

While only certain preferred features of the present invention have been illustrated and described,
25 many modifications and changes will be apparent to those skilled in the art. A modification is to arrange the stationary platform on a movable foundation included in a larger arrangement. It is therefore to be understood that all such modifications and changes of the present invention fall within the scope of the claims.

CLAIMS

1. An industrial robot (1) including a parallel kinematic manipulator (2) for movement of an object (7a) in space, where the manipulator (2) includes a stationary platform (6), a movable platform (7) for carrying the object (7a) and at least three arms (3, 4, 5) connecting the platforms (6, 7), characterized in that each of the at least three arms comprises a first arm part (9, 14, 23) connected to the stationary platform for endless rotation around an axis (A, E, F, G).
2. An industrial robot according to claim 1, wherein each of the at least three first arm parts (9, 14, 23) is arranged to rotate around one of at least two parallel axes (A, E, F, G).
3. An industrial robot according to claim 2, wherein the at least two axes of rotation (A, E, F, G) are arranged to coincide.
4. An industrial robot according to any preceding claim, wherein the stationary platform (6) comprises a column (6a).
5. An industrial robot according to claim 4, wherein the column (6a) is arranged with a detachable robot stand (8) in either end (35, 36) of the column.
6. An industrial robot according to claim 4, wherein the robot (1) is arranged in a ceiling position.
7. An industrial robot according to claim 4, wherein the robot (1) is arranged in a wall position.
8. An industrial robot according to claim 4, wherein the robot (1) is arranged in a floor position.
9. An industrial robot according to any preceding claim, wherein the manipulator (2) comprises four arms (3, 4, 5, 38).
10. An industrial robot according to any preceding claim, wherein the manipulator (2) comprises five arms (39, 40, 45, 46, 49).

11. An industrial robot according to any preceding claim, wherein the manipulator (2) comprises six arms (59, 60, 61, 62, 63, 64).
- 5 12. An industrial robot according to claim 11, wherein each of the six arms (59, 60, 61, 62, 63, 64) is connected to the movable platform (7) by one single link.
13. An industrial robot according to any preceding claim, wherein the manipulator (2) comprises at least one redundant arm (49, 51, 52).
- 10 14. A method in an industrial robot (1) including a parallel kinematic manipulator (2) for movement of an object (7a) in space, where the manipulator (2) includes a stationary platform (6), a movable platform (7) for carrying the object (7a), at least three arms (3, 4, 5) connecting the platforms (6, 7) and actuating means for actuating the arms, **c h a r a c t e r i z e d i n** that the actuating means are individually actuating the arms to endless rotation in different planes.
- 15 15. A method according to claim 14, wherein the at least three arms () are rotating around one of at least two parallel axes (E, F, G) in parallel planes.
- 20 16. A method according to claim 14, wherein the at least three arms (3, 4, 5) are rotating around a common axis (A) in parallel planes.
17. A method according to any of claims 14-16, wherein the arms (3, 4, 5) manipulate the object (7a) in constant inclination.
- 25 18. A method according to any of claims 14-17, wherein six robot arms (59, 60, 61, 62, 63, 64) are brought to manipulate the object (7a) in one degree of freedom each.
19. A method according to any of claims 14-18, wherein the operation volume of the robot is brought to vary during rotation.
- 30

20. A method according to any of claims 14-19, wherein at least one redundant arm (49, 51, 52) is bringing the object (7a) into endless rotation.
21. Use of an industrial robot according to claim 1-13 and a method according to claim 14-20 for high-accuracy operations.
22. Use of an industrial robot according to claim 1-13 and a method according to claim 14-20 for high-accuracy operations in clean rooms.

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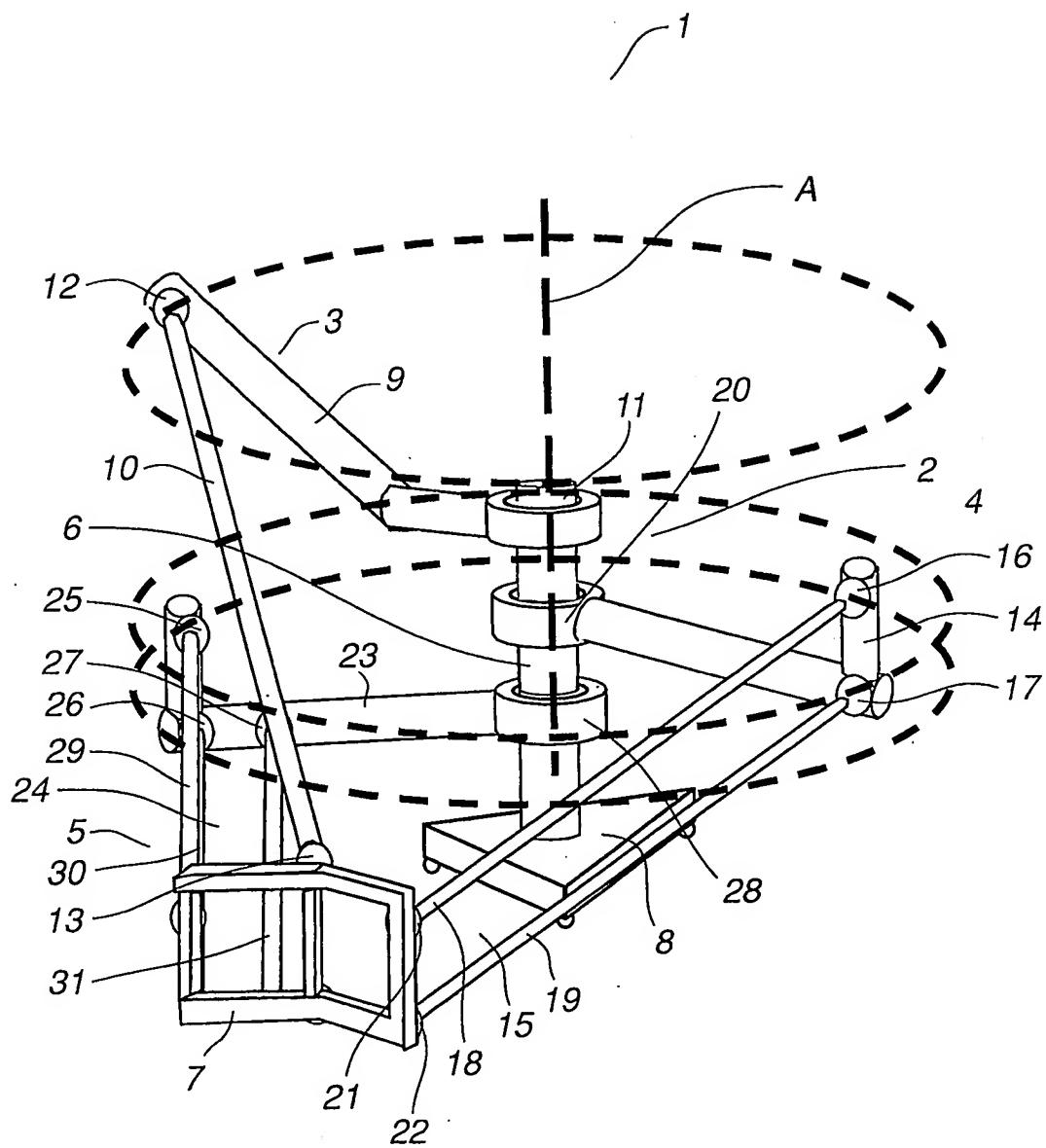


Fig. 1

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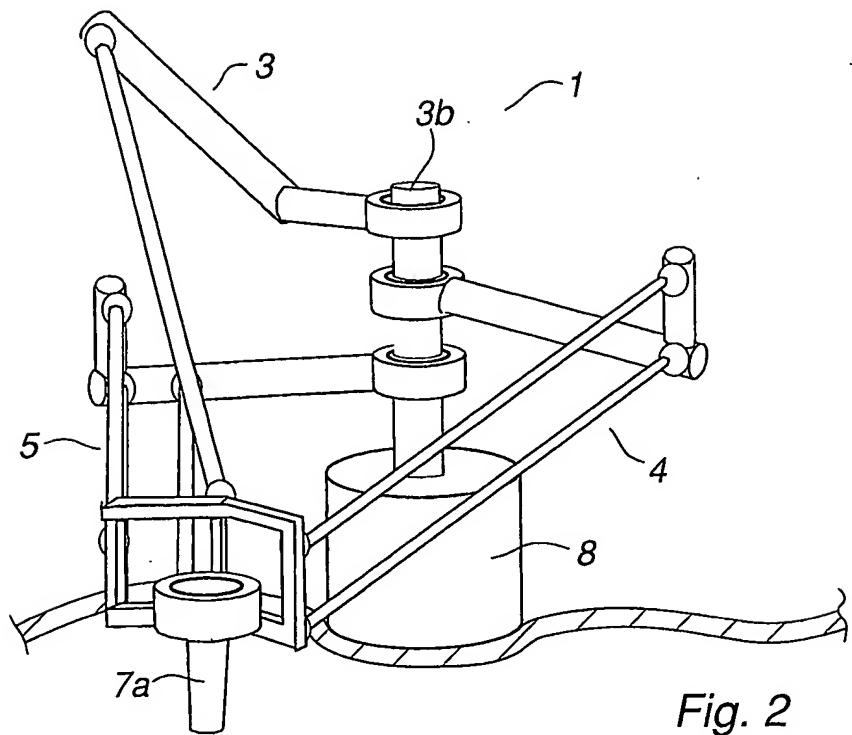


Fig. 2

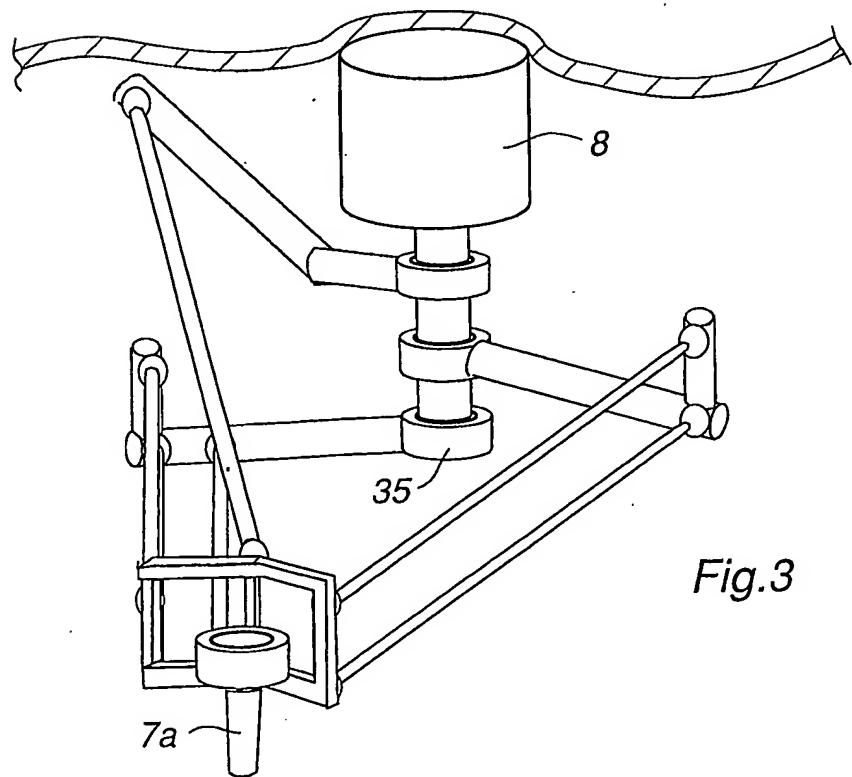


Fig. 3

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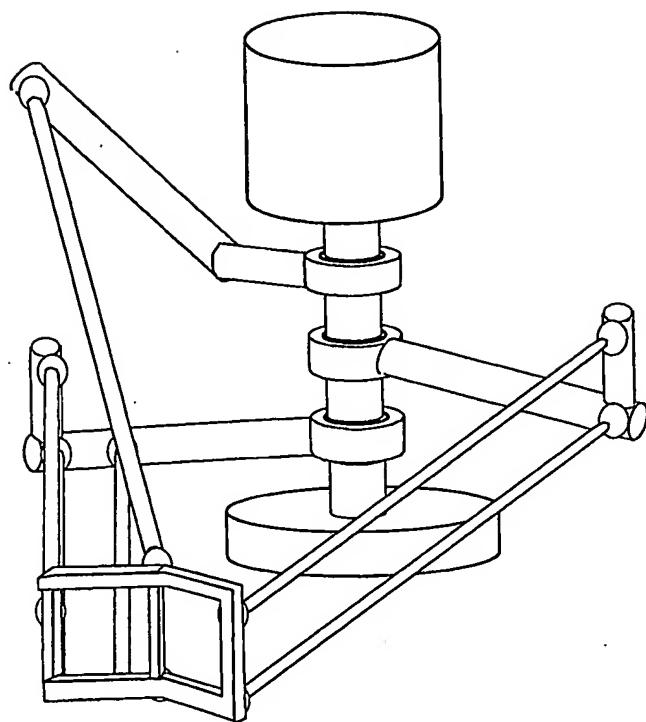


Fig. 4

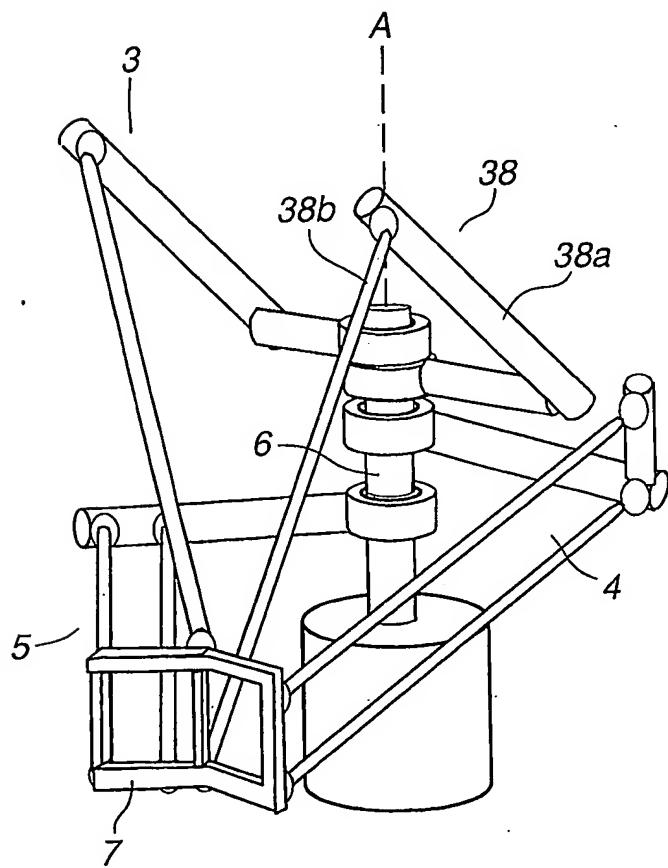


Fig. 5

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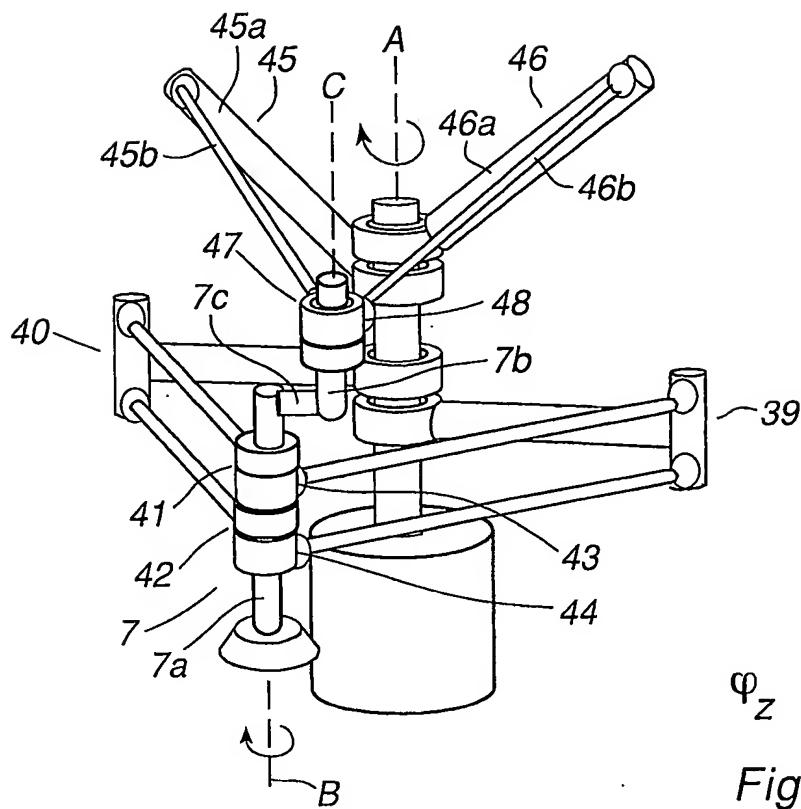


Fig. 6

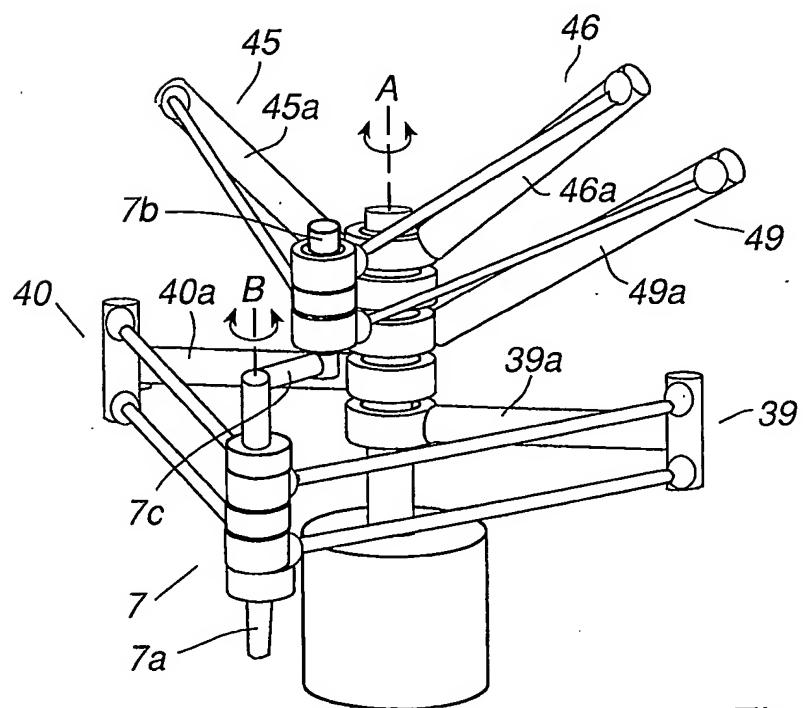


Fig. 7

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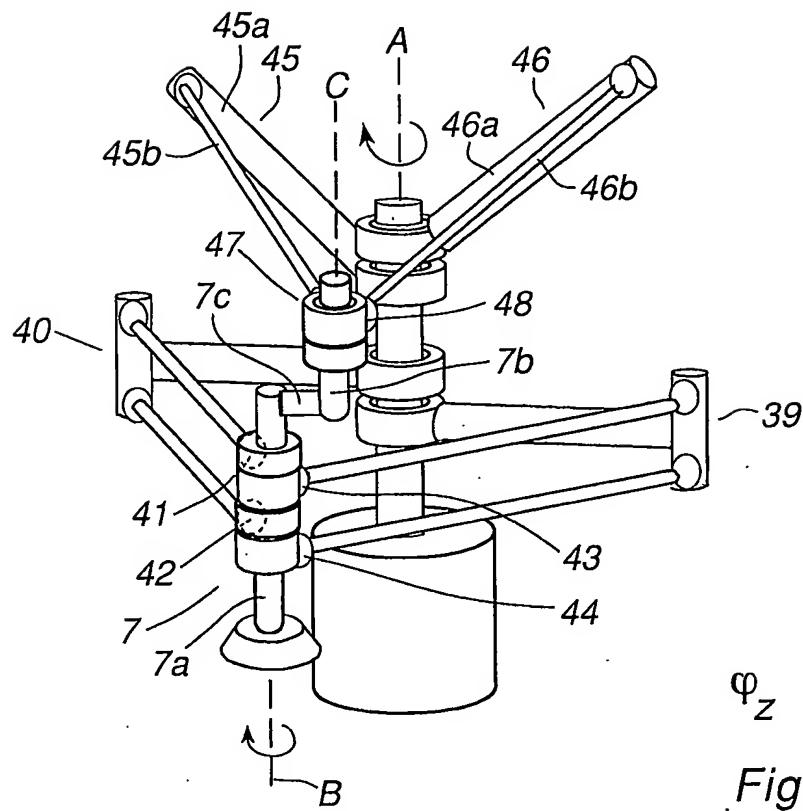


Fig. 6

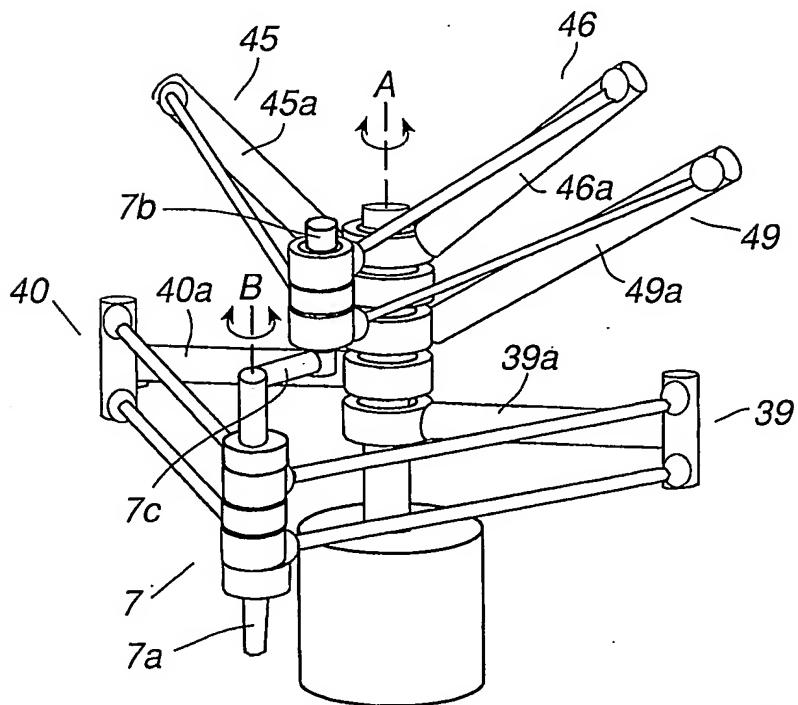


Fig. 7

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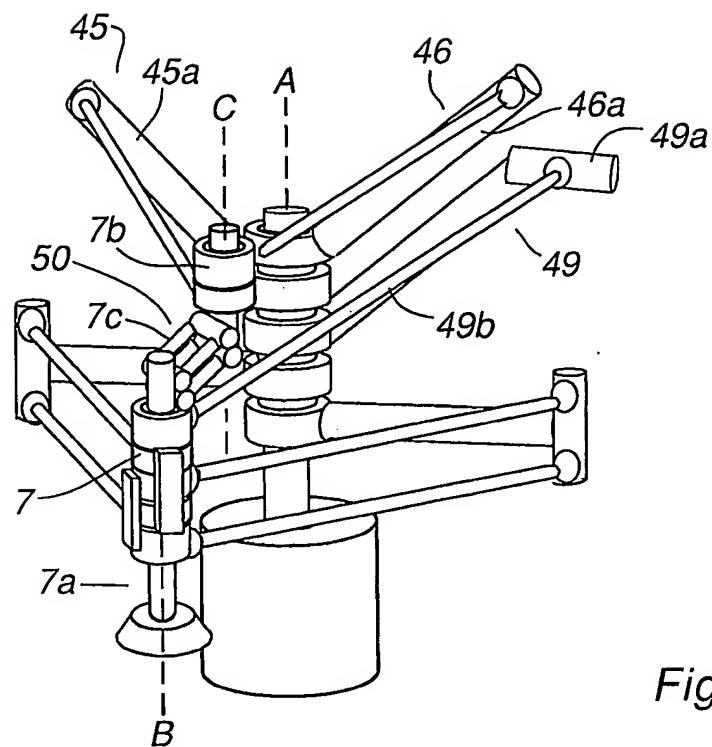


Fig. 8

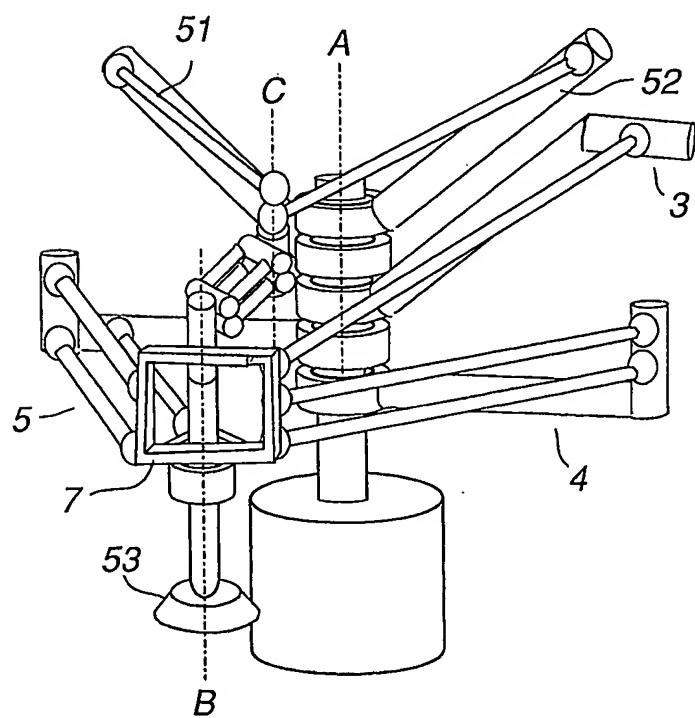


Fig. 9

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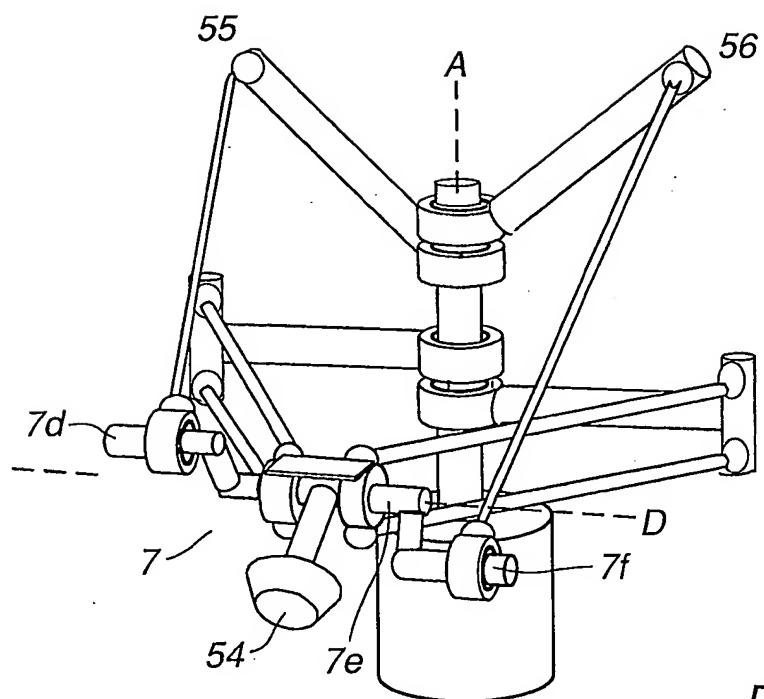


Fig. 10

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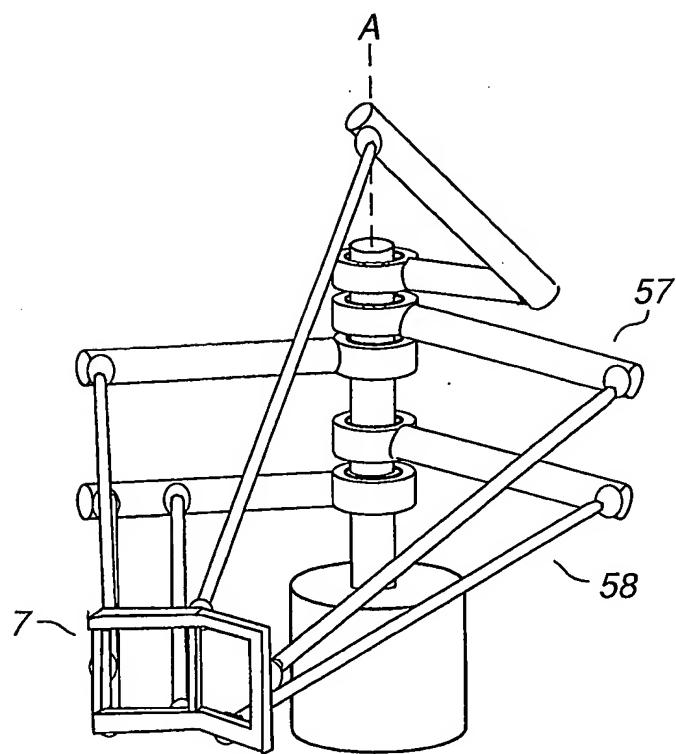


Fig. 11

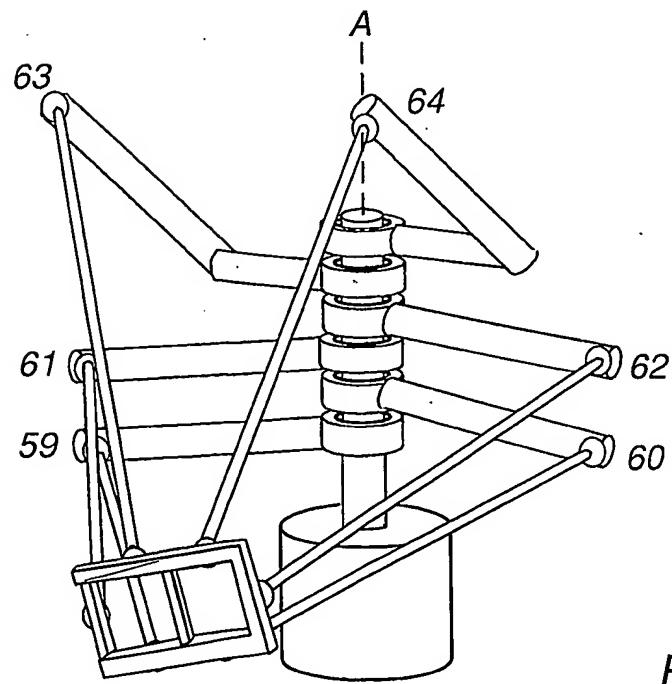


Fig. 12

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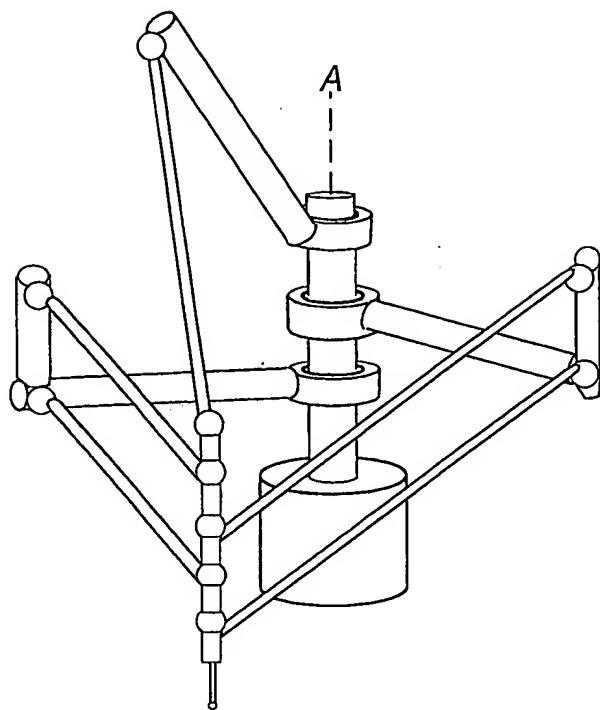


Fig. 13

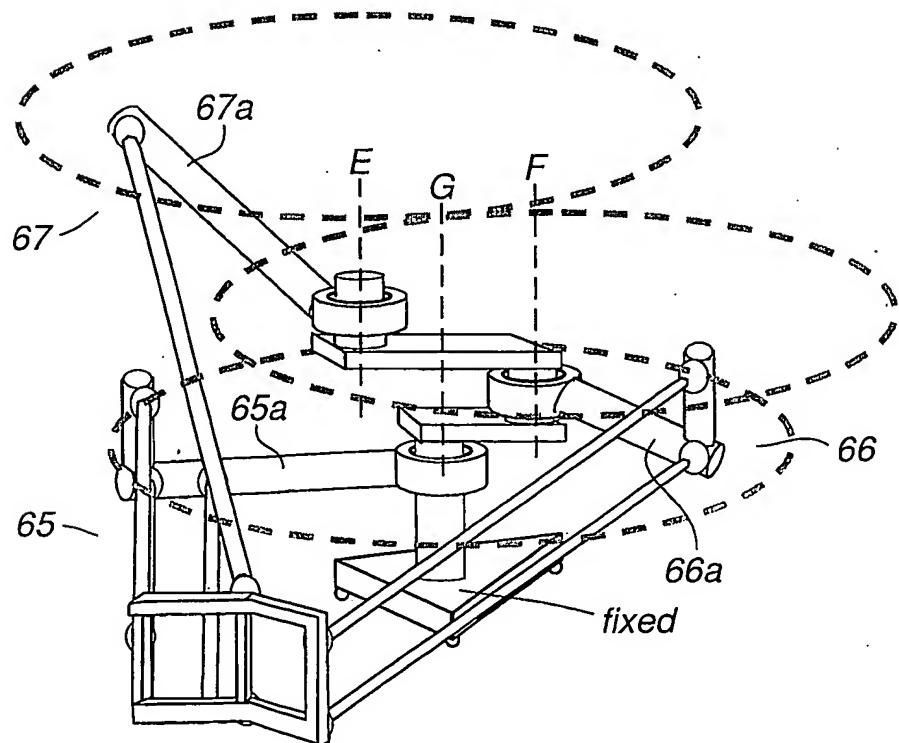


Fig. 14

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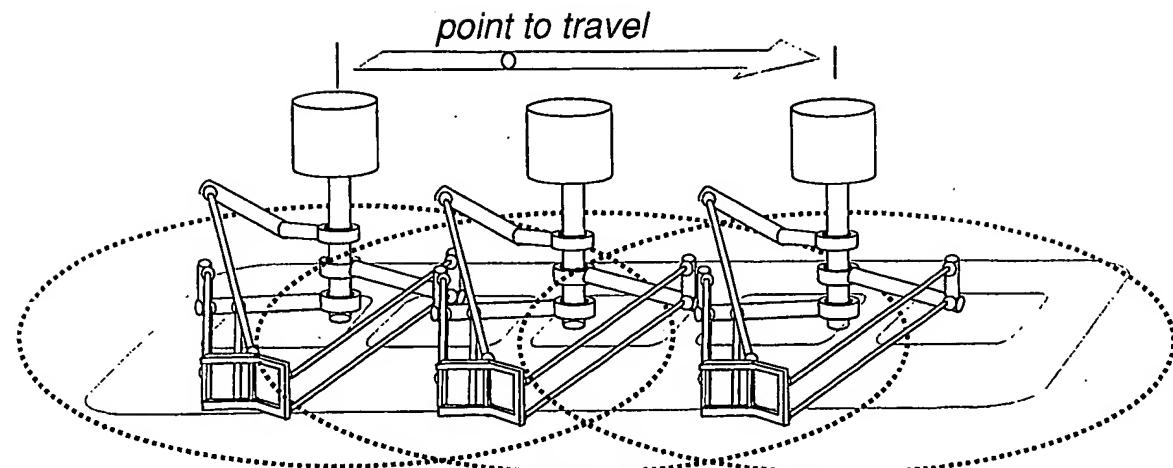
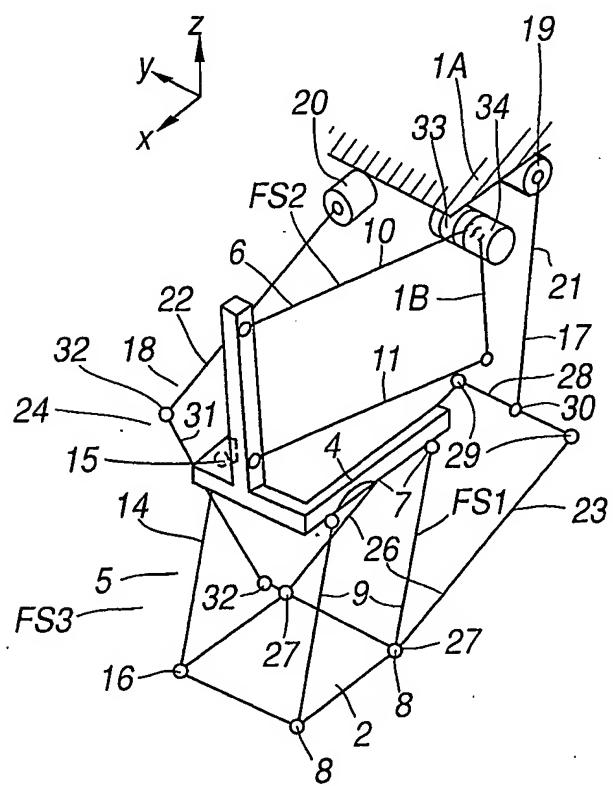


Fig. 15

Fig. 16
prior art

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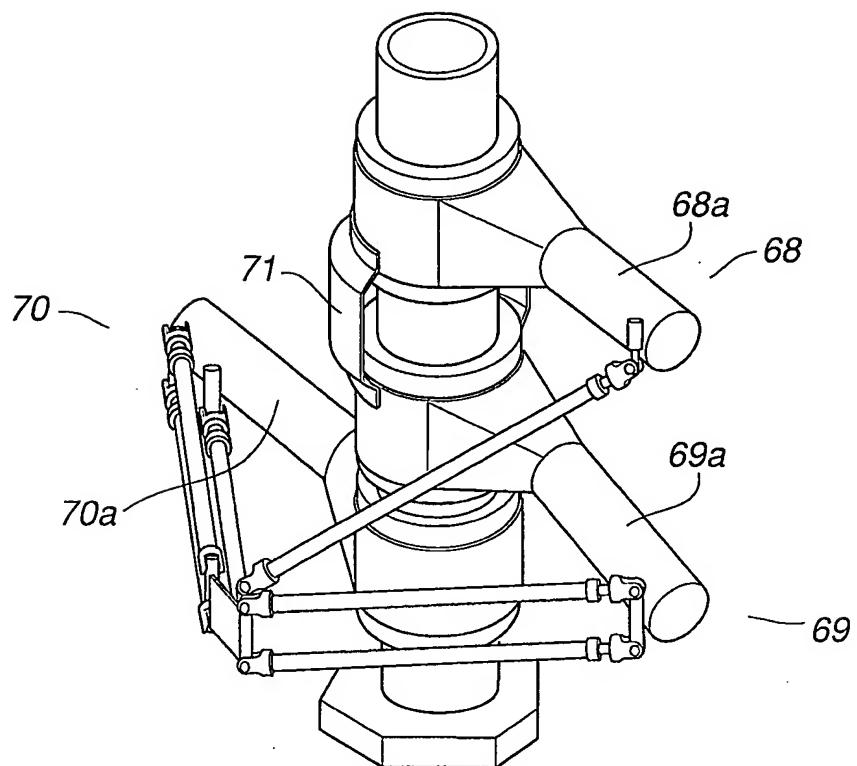


Fig. 17

INTERNATIONAL SEARCH REPORT

International application No.

PCT/SE 03/00200

A. CLASSIFICATION OF SUBJECT MATTER

IPC7: B25J 18/00, B25J 9/06, B25J 9/02

According to International Patent Classification (IPC) or to both national classification and IPC

B. FIELDS SEARCHED

Minimum documentation searched (classification system followed by classification symbols)

IPC7: B25J

Documentation searched other than minimum documentation to the extent that such documents are included in the fields searched

SE,DK,FI,NO classes as above

Electronic data base consulted during the international search (name of data base and, where practicable, search terms used)

EPO-INTERNAL,WPI,PAJ

C. DOCUMENTS CONSIDERED TO BE RELEVANT

Category*	Citation of document, with indication, where appropriate, of the relevant passages	Relevant to claim No.
X	US 5539291 A (REBOULET,C.), 23 July 1996 (23.07.96), column 3, line 46 - line 52; column 4, line 38 - line 44; column 5, line 49 - line 56, col. 6, li. 24-li.28,figure 2 --	1-22
P,A	WO 0222320 A1 (BROGARDH,T.), 21 March 2002 (21.03.02), whole document --	1-22
A	US 5857826 A (SATO,N.ET AL), 12 January 1999 (12.01.99), whole document --	1-22
A	US 5725352 A (TANAKA,S.), 10 March 1998 (10.03.98), the whole document --	1-22

Further documents are listed in the continuation of Box C.

See patent family annex.

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- "O" document referring to an oral disclosure, use, exhibition or other means
- "P" document published prior to the international filing date but later than the priority date claimed

"T" later document published after the international filing date or priority date and not in conflict with the application but cited to understand the principle or theory underlying the invention

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"Y" document of particular relevance: the claimed invention cannot be considered to involve an inventive step when the document is combined with one or more other such documents, such combination being obvious to a person skilled in the art

"&" document member of the same patent family

Date of the actual completion of the international search

10 April 2003

Date of mailing of the international search report

13-05-2003

Name and mailing address of the ISA/
Swedish Patent Office
Box 5055, S-102 42 STOCKHOLM
Facsimile No. + 46 8 666 02 86

Authorized officer

Gordana Ninkovic /itw
Telephone No. + 46 8 782 25 00

INTERNATIONAL SEARCH REPORT

International application No.

29/03/03

PCT/SE 03/00200

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